

## EAST SEARCH

5/12/04

L#	Hits	Search String	Databases
L2	11727	((robot\$3 or "autonomous vehicle") and camera	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB
L3	135	ubiquitous computing	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB
L4	11860	((robot\$3 or "autonomous vehicle") and camera) or "ubiquitous computing"	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB
L5	11498	((database or image\$1) with geometric\$2	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB
L7	645	((((robot\$3 or "autonomous vehicle") and camera) or "ubiquitous computing") and ((database or image\$1) with geometric\$2)	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB
L9	96	(((((robot\$3 or "autonomous vehicle") and camera) or "ubiquitous computing") and ((database or image\$1) with geometric\$2)) and (database with (entity or entities or object\$1)))	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB
L10	104	(((((robot\$3 or "autonomous vehicle") and camera) or "ubiquitous computing") and ((database or image\$1) with geometric\$2)) and (database with (build\$3 or input\$4 or update\$3 or maintain\$3)))	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB
L11	198	(((((robot\$3 or "autonomous vehicle") and camera) or "ubiquitous computing") and ((database or image\$1) with geometric\$2)) and ((entity or entities or object\$1) with relation\$4)	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB
L12	43	(((((robot\$3 or "autonomous vehicle") and camera) or "ubiquitous computing") and ((database or image\$1) with geometric\$2)) and (database same ((entity or entities or object\$1) with relation\$4)))	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB
L13	4	(((((robot\$3 or "autonomous vehicle") and camera) or "ubiquitous computing") and ((database or image\$1) with geometric\$2)) and (database same ((entity\$2 or entities\$1 or object\$2) with (size or extent or (service with (area or region)) ) ) ) ) )	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB
L2	66	(((((robot\$3 or "autonomous vehicle") and camera) or "ubiquitous computing") and ((database or image\$1) with geometric\$2)) and (database with (entity or entities or object\$1))) and (((robot\$3 or "autonomous vehicle") and camera) or "ubiquitous computing") and ((database or image\$1) with geometric\$2)) and ((entity or entities or object\$1) with relation\$4))	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB
L3	17	(((((robot\$3 or "autonomous vehicle") and camera) or "ubiquitous computing") and ((database or image\$1) with geometric\$2)) and (database same ((entity or entities or object\$1) with (query or queries)))	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB
L4	30	(((((robot\$3 or "autonomous vehicle") and camera) or "ubiquitous computing") and ((database or image\$1) with geometric\$2)) and (database with (query or queries)))	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB
L5	57	(((((robot\$3 or "autonomous vehicle") and camera) or "ubiquitous computing") and ((database or image\$1) with geometric\$2)) and (database same ((entity or entities or object\$1) with (identification) ) ) ) )	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB
L6	48	(((((robot\$3 or "autonomous vehicle") and camera) or "ubiquitous computing") and ((database or image\$1) with geometric\$2)) and ((entity or entities or object\$1) with identifier)	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB
L8	185	(((((robot\$3 or "autonomous vehicle") and camera) or "ubiquitous computing") and ((database or image\$1) with geometric\$2)) and ((entity or entities or object\$1) with measurement)	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB
L7	4	(((((robot\$3 or "autonomous vehicle") and camera) or "ubiquitous computing") and ((database or image\$1) with geometric\$2)) and (database same ((entity or entities or object\$1) with (size or extent or (service with (area or region)) ) ) ) ) )	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB
L9	6	(((((robot\$3 or "autonomous vehicle") and camera) or "ubiquitous computing") and ((database or image\$1) with geometric\$2)) and (database same ((entity or entities or object\$1) with measurement)))	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB

L10	99	(((robot\$3 or "autonomous vehicle" and camera) or "ubiquitous computing") and ((database or image\$1) with geometric\$2)) and ((entity or entities or object\$1) with relation\$4)) and (((robot\$3 or "autonomous vehicle" and camera) or "ubiquitous computing") and ((database or image\$1) with geometric\$2)) and ((entity or entities or object\$1) with measurement))	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB
L11	243	(((robot\$3 or "autonomous vehicle" and camera) or "ubiquitous computing") and ((database or image\$1) with geometric\$2)) and ((entity\$2 or entities\$1 or object\$2) with (size or extent or (service with (area or region))))	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB
	219	(((robot\$3 or "autonomous vehicle" and camera) or "ubiquitous computing") and ((database or image\$1) with geometric\$2)) and ( (size or extent or (service with (area or region))) with (polygon\$1 or line\$1 or point\$1))	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB
	142	(((robot\$3 or "autonomous vehicle" and camera) or "ubiquitous computing") and ((database or image\$1) with geometric\$2)) and ((entity\$2 or entities\$1 or object\$2) with (size or extent or (service with (area or region)))) and (((robot\$3 or "autonomous vehicle" and camera) or "ubiquitous computing") and ((database or image\$1) with geometric\$2)) and ( (size or extent or (service with (area or region))) with (polygon\$1 or line\$1 or point\$1))	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB
L1	55	(((robot\$3 or "autonomous vehicle" and camera) or "ubiquitous computing") and ((database or image\$1) with geometric\$2)) and ( (size or extent or (service with (area or region))) with (polygon\$1) with (polygon\$1))	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB
L2	54	(((robot\$3 or "autonomous vehicle" and camera) or "ubiquitous computing") and ((database or image\$1) with geometric\$2)) and ((entity\$2 or entities\$1 or object\$2) with (size or extent or (service with (area or region)))) and (((robot\$3 or "autonomous vehicle" and camera) or "ubiquitous computing") and ((database or image\$1) with geometric\$2)) and ( (size or extent or (service with (area or region))) with (polygon\$1))	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB
L3	128	(((robot\$3 or "autonomous vehicle" and camera) or "ubiquitous computing") and ((database or image\$1) with geometric\$2)) and ( (size or extent or (service with (area or region))) with (line\$1) with (line\$1))	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB
L4	91	image\$1 with geometric\$2)) and ((entity\$2 or entities\$1 or object\$2) with (size or extent or (service with (area or region)))) and (((robot\$3 or "autonomous vehicle" and camera) or "ubiquitous computing") and ((database or image\$1) with geometric\$2)) and ( (size or extent or (service with (area or region))) with (line\$1))	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB
	173	(((robot\$3 or "autonomous vehicle" and camera) or "ubiquitous computing") and ((database or image\$1) with geometric\$2)) and ( (size or extent or (service with (area or region))) with (point\$1) with (point\$1))	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB
	122	image\$1 with geometric\$2)) and ((entity\$2 or entities\$1 or object\$2) with (size or extent or (service with (area or region)))) and (((robot\$3 or "autonomous vehicle" and camera) or "ubiquitous computing") and ((database or image\$1) with geometric\$2)) and ( (size or extent or (service with (area or region))) with (point\$1))	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB



L17	37	13 and ((cycle\$1 or cyclical) with measure\$5)	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB
L18	37	8 and ((cycle\$1 or cyclical) with measure\$5)	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB
L14	9	13 and (line\$1 with segment\$1)	USPAT; US-PGPUB; EPO; JPO; DERWENT; IBM_TDB

09/657871	Barrett Brumitt
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5/12/04

Results of search set L10:((((robot\$3 or "autonomous vehicle") and camera) or "ubiquitous computing") and ((database or image\$1) with geometric)).  
and (database with (entity or entities or object\$1))

DocumentKind	Codes	Title	Issue Date	Current OR	Abstract
US 20030209893	A1	Occupant sensing system	20031113	280735	
US 20030206115	A1	Location measurement process for radio-frequency badges	20031106	340/825.49	
US 20030195883	A1	System and method for measuring image similarity based on semantic meaning	20031016	707/6	
US 20030174286	A1	Method and apparatus for producing dynamic imagery in a visual medium	20030918	352/243	
US 20030174285	A1	Method and apparatus for producing dynamic imagery in a visual medium	20030918	352/85	
US 20030037075	A1	Digital watermarking methods and related toy and game applications	20030220	715/500	
US 20020151992	A1	Media recording device with packet data interface	20021017	700/83	
US 20020126897	A1	Motion information recognition system	20020912	382/197	
US 20020116200	A1	SATELLITE BASED GLOBAL POSITIONING SYSTEM FOR FEEDLOT COMPUTER NETWORK AI	20020822	705/1	
US 20020077787	A1	Textual and graphical demarcation of location, and interpretation of measurements	20020620	702/188	
US 20020032697	A1	Time inheritance scene graph for representation of media content	20020314	715/500.1	
US 20020007798	A1	Apparatus and method for delivering feed rations along a feedbunk using a global positioning system	20020124	119/51.01	
US 20010043219	A1	INTEGRATING LIVE/RECORDED SOURCES INTO A THREE-DIMENSIONAL ENVIRONMENT FO	20011122	345/474	
US 6647146	B1	Image processing apparatus	20031111	382/199	
US 6640145	B2	Media recording device with packet data interface	20031028	700/83	
US 6556783	B1	Method and apparatus for three dimensional modeling of an object	20030429	396/20	
US 6516270	B2	Apparatus and method for delivering feed rations along a feedbunk using a global positioning system	20030204	701/213	
US 6516099	B1	Image processing apparatus	20030204	382/284	
US 6512518	B2	Integrated system for quickly and accurately imaging and modeling three-dimensional objects	20030128	345/427	
US 6483938	B1	System and method for classifying an anomaly	20021119	382/149	
US 6473079	B1	Integrated system for quickly and accurately imaging and modeling three-dimensional objects	20021029	345/419	
US 6420698	B1	Integrated system for quickly and accurately imaging and modeling three-dimensional objects	20020716	250/234	
US 6418424	B1	Ergonomic man-machine interface incorporating adaptive pattern recognition based control system	20020709	706/21	
US 6411862	B1	Apparatus and method for managing and distributing design and manufacturing information throughc	20020625	700/182	
US 6411266	B1	Apparatus and method for providing images of real and virtual objects in a head mounted display	20020625	345/8	
US 6400996	B1	Adaptive pattern recognition based control system and method	20020604	700/83	
US 6330523	B1	Integrated system for quickly and accurately imaging and modeling three-dimensional objects	20011211	702/159	
US 6266053	B1	Time inheritance scene graph for representation of media content	20010724	715/500.1	
US 6246468	B1	Integrated system for quickly and accurately imaging and modeling three-dimensional objects	20010612	356/4.02	
US 6226783	B1	Object oriented method of structuring a software step program	20010501	717/104	
US 6222482	B1	Hand-held device providing a closest feature location in a three-dimensional geometry database	20010424	342/357.08	
US 6216053	B1	Apparatus and method for uniformly delivering feed rations along a feedbunk using global positioning	20010410	700/104	
US 6212441	B1	Apparatus and method for managing and distributing design and manufacturing information throughc	20010403	700/98	
US 6173066	B1	Pose determination and tracking by matching 3D objects to a 2D sensor	20010109	382/103	
US 6160907	A	Iterative three-dimensional process for creating finished media content	20010121	382/154	
US 6124864	A	Adaptive modeling and segmentation of visual image streams	20000926	345/473	
US 6084590	A	Media production with correlation of image stream and abstract objects in a three-dimensional virtual	20000704	345/419	
US 6072903	A	Image processing apparatus and image processing method	20000606	382/190	
US 6054990	A	Computer system with handwriting annotation	20000425	345/863	
US 6032084	A	System for carrying out and managing animal feedlot operations using coordinate acquisition technic	20000229	700/241	
US 5988862	A	Integrated system for quickly and accurately imaging and modeling three dimensional objects	19991123	703/6	
US 5905499	A	Method and system for high performance computer-generated virtual environments	19990518	345/419	
US 5886897	A	Apparatus and method for managing and distributing design and manufacturing information throughc	19990323	700/182	
US 5696892	A	Method and apparatus for providing animation in a three-dimensional computer generated virtual wor	19971209	345/582	
US 5495576	A	Panoramic image based virtual reality/telepresence audio-visual system and method	19960227	345/420	
US 5487172	A	Transform processor system having reduced processing bandwidth	19960123	712/32	

US 4825394 A	Vision metrology system	19890425 356/147
US 4697239 A	Automated installation for processing large objects	19870929 700/113
WO 200141546 A	Computer-implemented process for providing geometric model database for responding to queries a	20010614